



096030-000101

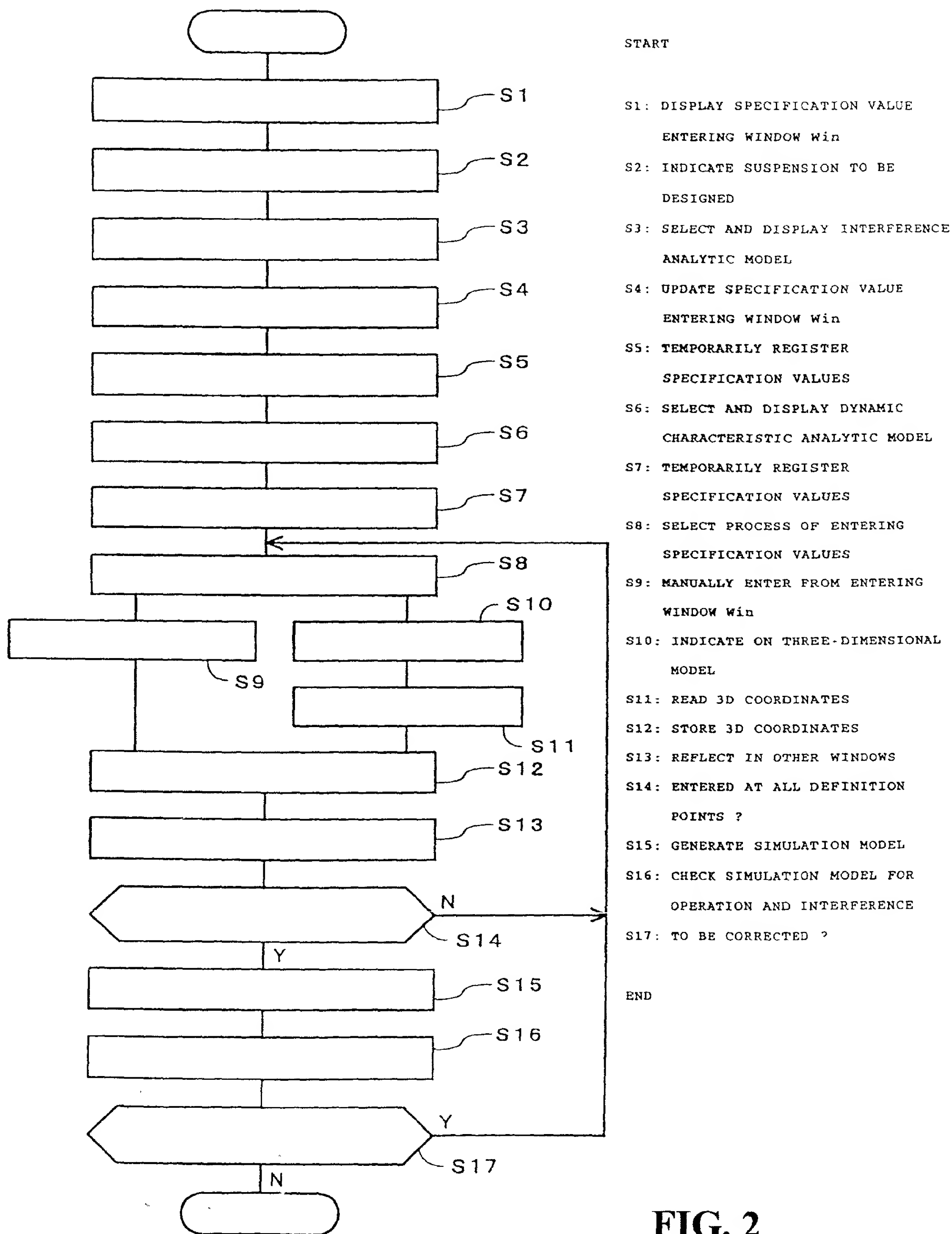


FIG. 2

0432030.060101

Select TYPE

POWER TRAIN	SUS-TYPE	STRG.-TYPE	CUSH.-MOUNT
4WD	DOUBLE W. B.	ARM	UPPER

301 302 303 304 30

Kinematics Coordinate			Geometry	
	T	B	H	
A	.00	.00	.00	ANG .00 D1 .00
B	.00	.00	.00	LENG1 .00 D2 .00
C	.00	.00	.00	L1 .00 D3 .00
D	.00	.00	.00	L2 .00 D4 .00
E	.00	.00	.00	L3 .00 D5 .00
F	.00	.00	.00	PHAI1 .00 D6 .00
G	.00	.00	.00	PHAI2 .00 D7 .00
H	.00	.00	.00	PHAI3 .00 R1 .00
P	.00	.00	.00	ARM .00 R2 .00
Q	.00	.00	.00	Figure R3 .00
R	.00	.00	.00	R4 .00
S	.00	.00	.00	
T	.00	.00	.00	
U	.00	.00	.00	
V	.00	.00	.00	
W	.00	.00	.00	
$\theta$	.00	Figure		

31 32

Win

FIG. 3

The diagram, titled "Kinematics coord", illustrates a mechanical linkage system. A wheel on the left is connected to a lever arm (62) at point A. The lever arm (62) pivots at point B and is connected to a vertical link (65) at point C. This link (65) is part of a parallelogram linkage with points A, B, C, and W. A second lever arm (61) is pivoted at point F and connected to point G. A spring (63) is attached to point T and point U. A vertical link (64) connects point R to point S. A separate link is shown at an angle  $\theta$ . A "Close" button is in the bottom left, and a "Wkc" label is in the bottom right.

**FIG. 4**

Select TYPE

POWER TRAIN

2WD

SUS-TYPE

DOUBLE W. B.

STRG. -TYPE

ARM

CUSH. -MOUNT

UPPER

Kinematics Coordinate

	T	B	H
A	.00	.00	.00
B	.00	.00	.00
C	.00	.00	.00
D			
E	.00	.00	.00
F	.00	.00	.00
G	.00	.00	.00
H			
P			
Q	.00	.00	.00
R	.00	.00	.00
S	.00	.00	.00
T	.00	.00	.00
U	.00	.00	.00
V	.00	.00	.00
W			
θ .00 Figure			

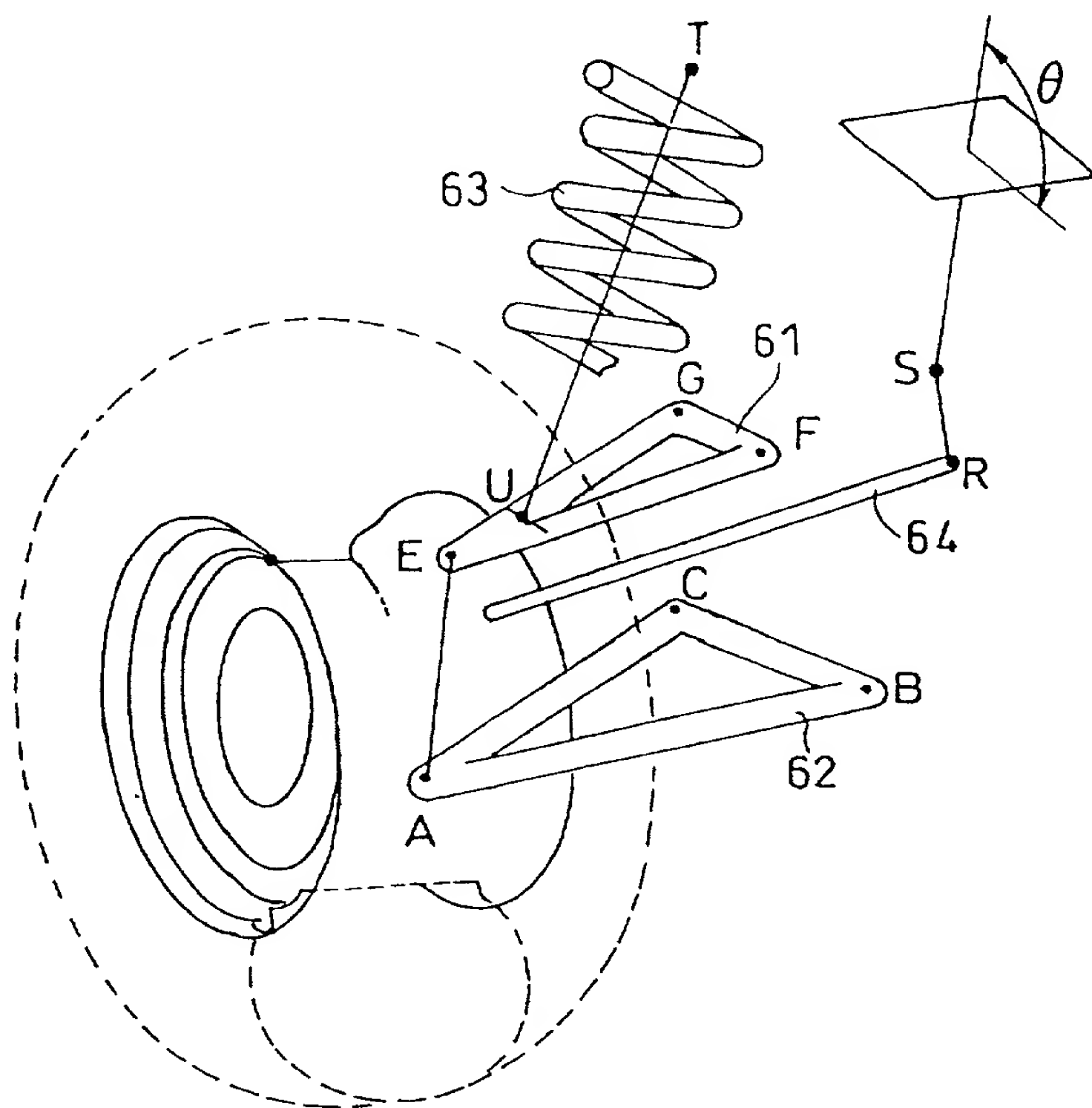
Geometry

ANG	.00	D1	.00
LENG1	.00	D2	.00
L1	.00	D3	.00
L2	.00	D4	.00
L3	.00	D5	.00
PHAI1	.00	D6	.00
PHAI2	.00	D7	.00
PHAI3	.00	R1	.00
ARM	.00	R2	.00
Figure		R3	.00
		R4	.00

**FIG. 5**

**FIG. 5**

Kinematics coord



Close

Wkc

FIG. 6

Select TYPE		
POWER TRAIN	SUS-TYPE	STRG. -TYPE
2WD	DOUBLE W. B.	ARM
CUSH. -MOUNT		
LOWER		

### Kinematics Coordinate

	T	B	H
A	.00	.00	.00
B	.00	.00	.00
C	.00	.00	.00
D	.00	.00	.00
E	.00	.00	.00
F	.00	.00	.00
G	.00	.00	.00
H	.00	.00	.00
P	.00	.00	.00
Q	.00	.00	.00
R	.00	.00	.00
S	.00	.00	.00
T	.00	.00	.00
U	.00	.00	.00
V	.00	.00	.00
W	.00	.00	.00
$\theta$	Figure		

### Geometry

ANG	.00	D1	.00
LENG1	.00	D2	.00
L1	.00	D3	.00
L2	.00	D4	.00
L3	.00	D5	.00
PHAI1	.00	D6	.00
PHAI2	.00	D7	.00
PHAI3	.00	R1	.00
ARM	.00	R2	.00
Figure		R3	.00
		R4	.00

FIG. 7

The diagram illustrates a mechanical system with the following components and connections:

- Base and Platform:** A large dashed circle represents a base. A horizontal disk is mounted on a vertical axis passing through point **J**. The disk is tilted at an angle  $\theta$  relative to the vertical axis.
- Link 62:** A triangular link with vertices **A**, **B**, and **C**. It is pivoted at point **A** to the base.
- Link 64:** A long, thin link pivoted at point **R** on the platform and point **E** on link 62.
- Spring 63:** A coiled spring connecting point **T** (on the platform) to point **G** (on link 62).
- Other Points:** Point **U** is located on link 62. Point **F** is at the end of link 64. Point **S** is on the platform.

Wkc

**FIG. 8**



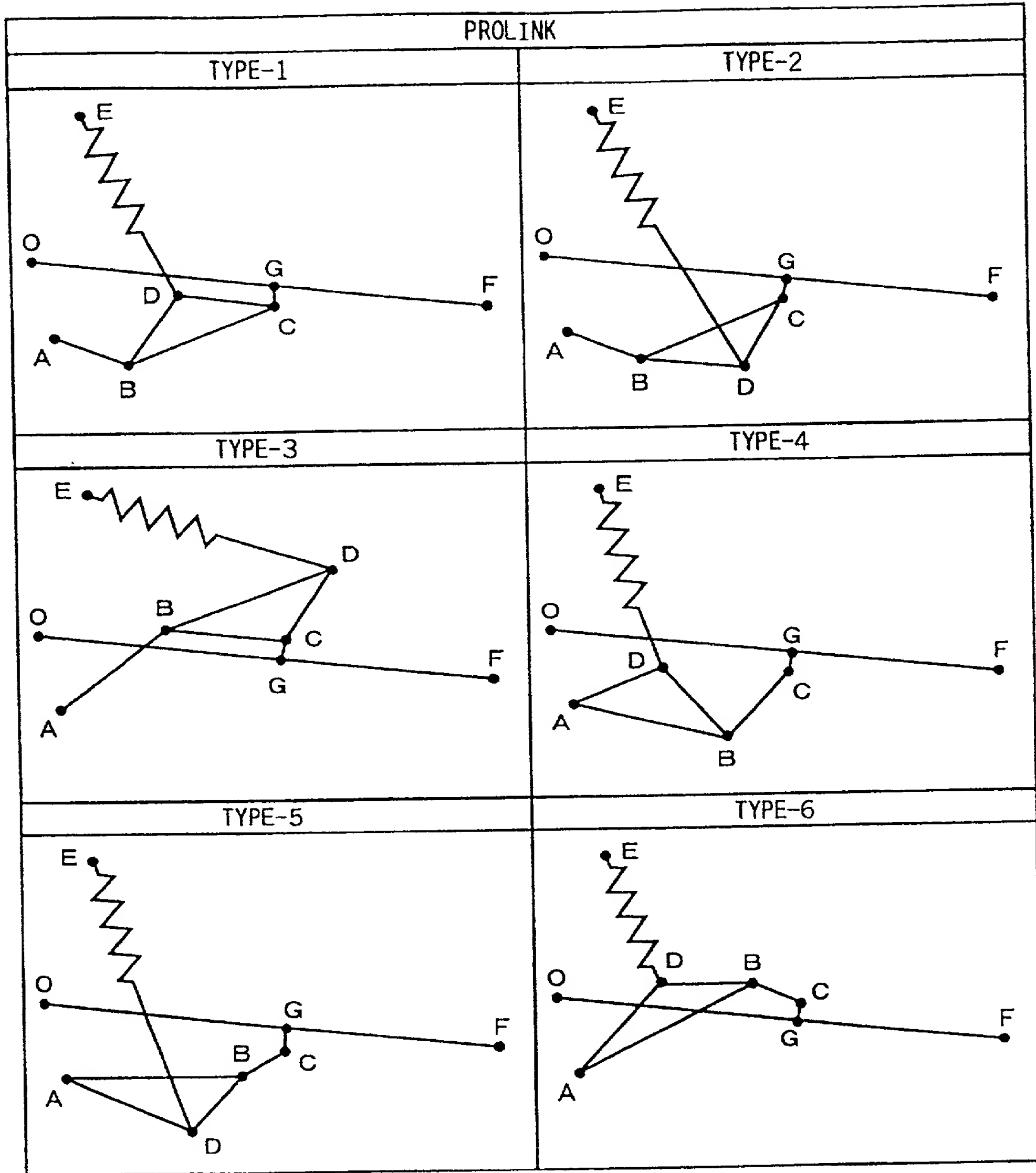


FIG. 9

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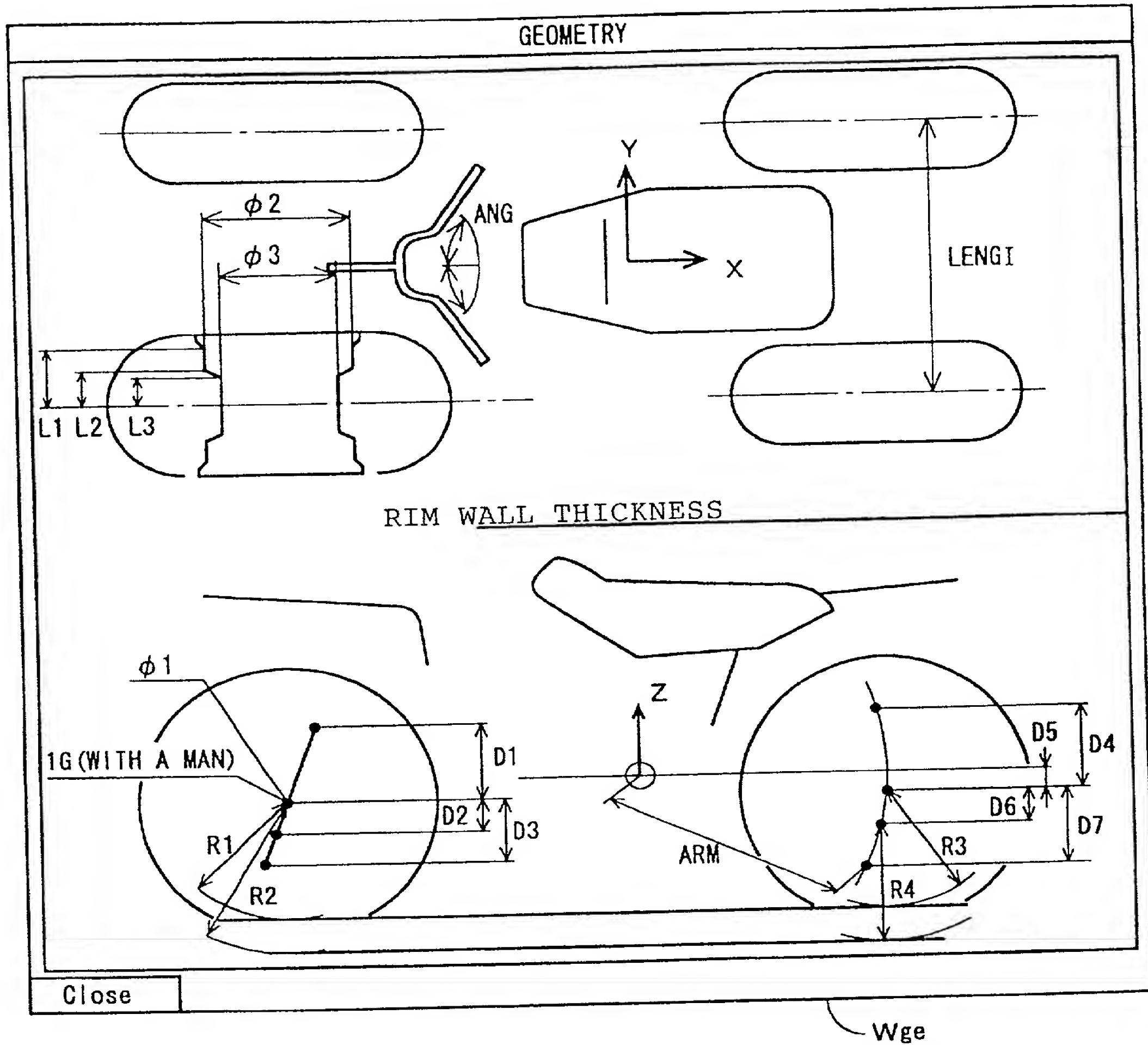
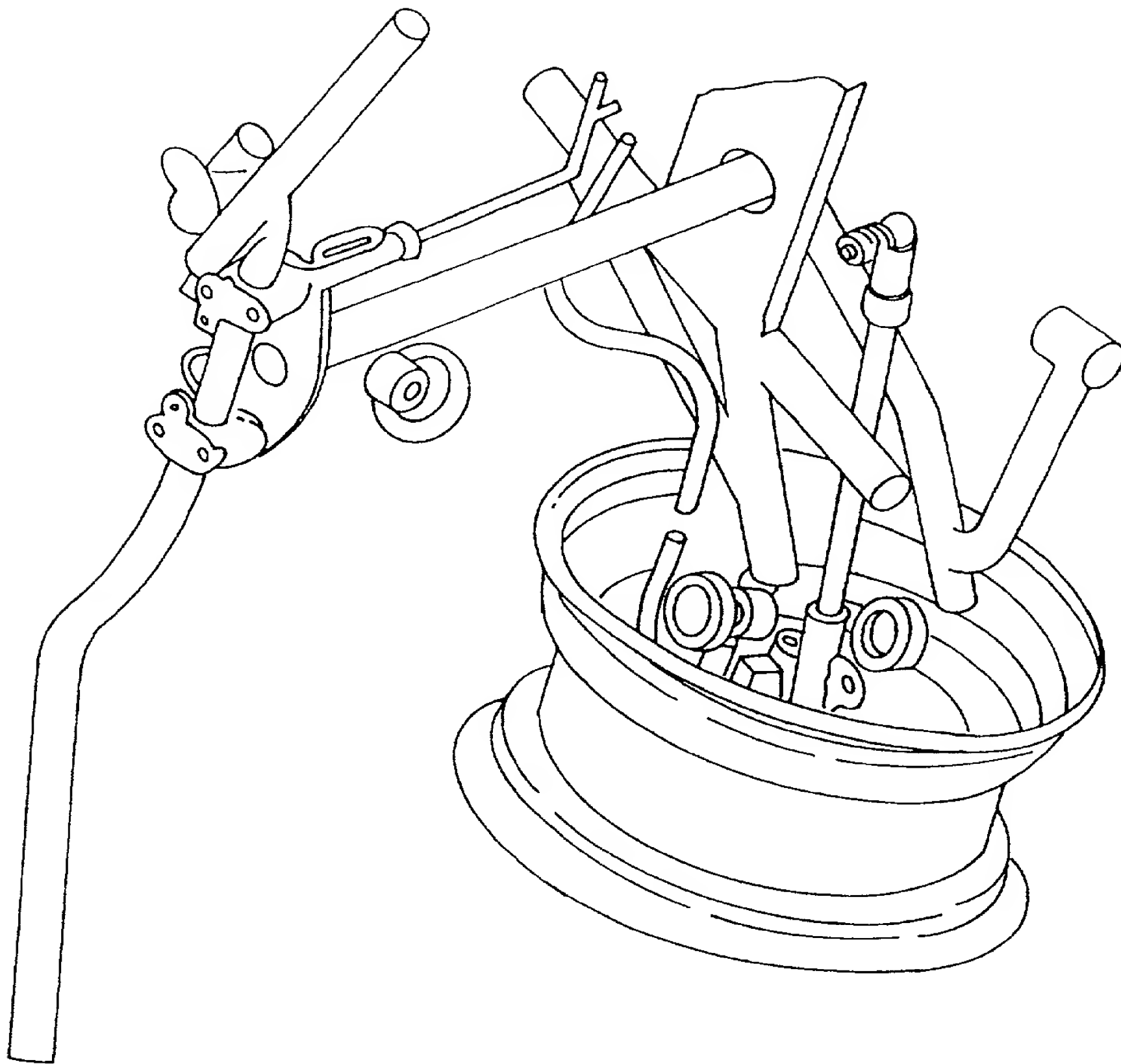


FIG. 10

FIG. 11



**FIG. 11**